

```
graspObject(Z) {
```

```
  x = estimateState(Z);
```

```
  pick_target = planGrasp(x);
```

```
  traj = findTrajectory(x, pick_target);
```

```
  grasp_quality = motorController(traj);
```

```
  return grasp_quality;
```

```
}
```

a)

b)

